

**Amendments to the Specification**

Page 1, after the "Title" of the invention please insert the following headings:

**Background of the Invention**

**Technical Field**

Page 1, after line 14, please insert the following heading:

**Prior Art**

Page 2, after line 3, please insert the following heading:

**Object and Summary of the Invention**

Page 5, before line 1, please insert the following heading:

**Brief Description of the Drawings**

Page 5, after line 10, please insert the following new paragraphs and heading:

Fig. 4 shows an enlarged section of the roller positioning of Fig. 3.

Fig. 5 shows an enlarged section of the magazine compartments of Fig. 3.

**Detailed Description of the Preformed Embodiment(s) of the Invention**

Please replace the paragraphs beginning on page 5, line 39, to page 6, line 18, with the following amended paragraphs:

Additional rollers W1 - W6 with different contours and/or dimensions are stored in magazine compartments M1 - M6 of magazines M, their coupling K oriented in such a way, that the robot R1 can connect it to the complementary coupling K1 after disconnecting and depositing the previous roller W1. If the robot does not control directly, by way of a gripper, the complementary coupling K1, the coupling section K of the roller W1 is inserted, for example, into a ~~fork~~ coupling release device GL of the corresponding magazine compartment M1, the insertion into the ~~fork~~ coupling release device GL then actuating a release mechanism. The release permits the robot R1 to withdraw the complementary coupling K1

from the coupling K, and to connect to another roller by reversing the process, and to take it out of the magazine.

As shown in Fig. 4 ~~Tthe coupling K1 shows, has towards the complementary coupling K1, centring means CM such as an inner and an outer cone or pyramid-shape, angular orientation means AOM such as radial extensions and grooves, as well as axial limit stops AL or edges, towards the complementary coupling K1 which, combined, result in a definite positioning of the roller W2, when the coupling is latched or locked with the locking pieces LP.~~

As shown in more detail in Fig. 5 ~~tThe resilience of the locking in a magazine compartment M1, M2 is advantageously produced by a spring, the latter being connected to spreading levers, which cooperate with a spreader and an actuator or button L on the magazine compartment and a show coupling release device GL, to release the coupling K1.~~

The motors of the ~~robot~~ multi-axis positioning device RA1 are equipped with brakes, which are actuated by an electromagnetic, pneumatic or hydraulic central control. However, the installation of self-locking transmissions subsequent to the motor is preferable.

Before the claims please insert the following as a new page:

Reference list

AOM angular orientation means

B message bus

CM centring means

F covering material

FR roller conveyor

G stand

GL coupling release device

H holder

K coupling

K1 complementary coupling

L release button

LP locking piece

M magazine

M1-M6 magazine compartment

MO, TA controlling and operating means

P profile material

Appln. No. 10/589,020  
Amd. dated July 17, 2008  
Reply to Office Action of March 17, 2008

R1-R16 robots

RA1 multi-axis positioning device

SP memory

ST master controller

W1-W6 pressure roller